

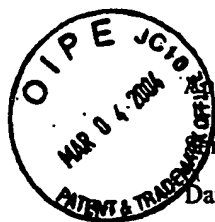
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GF	Vos, D., <i>Dynamics and Nonlinear Adaptive Control of an Autonomous Unicycle</i> , Massachusetts Institute of Technology, 1989				
GG	Vos, D., <i>Nonlinear Control of an Autonomous Unicycle Robot: Practical Issues</i> , Massachusetts Institute of Technology, 1992				
GH	Koyanagi et al., <i>A Wheeled Inverse Pendulum Type Self-Contained Mobile Robot and its Posture Control and Vehicle Control</i> , <u>The Society of Instrument and Control Engineers</u> , Special issue of the 31 st SICE Annual Conference, Japan 1992, pp. 13-16.				
GI	Koyanagi et al., <i>A Wheeled Inverse Pendulum Type Self-Contained Mobile Robot</i> , <u>The Society of Instrument and Control Engineers</u> , Special issue of the 31 st SICE Annual Conference, Japan 1992, pp. 51-56				
GJ	Koyanagi et al., <i>A Wheeled Inverse Pendulum Type Self-Contained Mobile Robot and its Two Dimensional Trajectory Control</i> , <u>Proceeding of the Second International Symposium on Measurement and Control in Robotics</u> , Japan 1992, pp. 891-898.				
GK	Watson Industries, Inc., Vertical Reference Manual ADS-C132-1A, 1992, pp. 3-4				
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SECTION 2. FORMS PTO/SB/08A and 08B (formerly Form PTO-1449)

IN THE UNITED STATES PATENT AND TRADEMARK OFFICE



Applicants: Dean L. Kamen, et al.

Attorney Docket: 1062/D77

Serial No: 10/617,598

Art Group Unit: 3611

Date Filed: July 11, 2003

Examiner Name: Not yet assigned

Invention: Control of a Transporter Based on Attitude

**LIST OF PATENTS AND PUBLICATIONS FOR
APPLICANT'S INFORMATION DISCLOSURE STATEMENT**

Ref. No.	U.S. Patent No.	Inventor	Issue Date	See Sec. 1	Exam. Init.
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